

**Amendments to the Claims:**

Claims 1-18 **(Cancelled)**

19. **(New)** A manipulator-type robot arrangement for connection to at least one of first external device signal lines of a first external device and second external device signal lines of a second external device, comprising:

a manipulator including a manipulator connection case;

an internal cable routed through an inside of said manipulator, said internal cable including a plurality of signal lines;

inside connectors provided in said connection case, each of said inside connectors being connected, directly or indirectly, to one of said plurality of signal lines of said internal cable;

first outside connectors provided in said connection case and being configured to be connected, directly or indirectly, to the first external device signal lines of the first external device; and

second outside connectors provided in said connection case and being configured to be connected, directly or indirectly, to the second external device signal lines of the second external device;

wherein said inside connectors, said first outside connectors, and said second outside connectors are configured to enable a selective connection between at least part of said inside connectors, at least part of said first outside connectors, and at least part of said second outside connectors so as to enable selection of different connection routes between said inside connectors, said first outside connectors, and said second outside connectors.

20. **(New)** The manipulator-type robot arrangement according to claim 19, further comprising

a first internal connector provided in said connection case and connected, directly or indirectly, to said first outside connectors, said first internal connector being arranged for connection to a first external connector connected to the first external device.

21. (New) The manipulator-type robot arrangement according to claim 20, further comprising

a second internal connector provided in said connection case and connected, directly or indirectly, to said second outside connectors, said second internal connector being arranged for connection to a second external connector connected to the second external device.

22. (New) The manipulator-type robot arrangement according to claim 19, further comprising

a first internal connector provided in said connection case and connected, directly or indirectly, to said first outside connectors; and

a first external connector provided outside said connection case and adapted to connect to the first external device signal lines of the first external device, said first external connector being configured for connection to said first internal connector.

23. (New) The manipulator-type robot arrangement according to claim 22, further comprising

a second internal connector provided in said connection case and connected, directly or indirectly, to said second outside connectors; and

a second external connector provided outside said connection case and adapted to connect to the second external device signal lines of the second external device, said second external connector being configured for connection to said second internal connector.

24. (New) The manipulator-type robot arrangement according to claim 19, further comprising

a first internal connector provided in said connection case and connected, directly or indirectly, to said first outside connectors;

the first external device having the first external device signal lines; and

a first external connector provided outside said connection case and connected to said first external device signal lines of said first external device, said first external connector being configured for connection to said first internal connector.

25. (New) The manipulator-type robot arrangement according to claim 24, wherein said first external device signal lines are bundled together as a first external cable.

26. (New) The manipulator-type robot arrangement according to claim 24, wherein said first external device comprises a controller for controlling the manipulator.

27. (New) The manipulator-type robot arrangement according to claim 24, further comprising

a second internal connector provided in said connection case and connected, directly or indirectly, to said second outside connectors;

the second external device having the second external device signal lines; and

a second external connector provided outside said connection case and connected to said second external device signal lines of said second external device, said second external connector being configured for connection to said second internal connector.

28. (New) The manipulator-type robot arrangement according to claim 27, wherein said second external device signal lines are bundled together as a second external cable.

29. (New) The manipulator-type robot arrangement according to claim 27, wherein said first external device comprises a controller for controlling the manipulator; and

said second external device comprises a peripheral device including a positioner and a sensor.

30. (New) The manipulator-type robot arrangement according to claim 29, wherein said first external device is connected to said second external device via said first and second external connectors.